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3 and (camera\$1 or "CCD" or imag\$3 near3 devic\$2 or image-pickup or image near3 captur\$3 or sensor\$@ or sensing near3 device\$1)	(robot\$4 or mechanical\$4 or mechaniz\$5 or mechanis\$5)  near7 (pen\$1 or penlike\$1 or pencil\$3 or pencillike\$1 or pencil\$3 or pencillike\$1 or pencil adj1 like\$1 or handwrit\$4 or writ\$4 or hand adj1 (writ\$4 or print\$4) or scrib\$4 or print\$4 or penmanship\$4 or lineart or line adj1 (drawing\$! or art adj1 (drawing\$! or art adj1 (drawing\$1 or work\$3))  and (382.clas. or 901.clas. or 706.clas. or 345.clas. or 700.clas. or 356.clas. or 250.clas. or 359.clas.)	search Text
USPAT; US-PGP UB; EPO; 2004 JPO; 14:3 T; IBM_TD B	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	בפט
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S 4 ω BRS IS&R BRS Туре L7 16 L6 L5 r # 10 29 40 Hits or ("4864966") or ഗ vision near3 system) vision near3 4 and (vision-based or (("5521829") or ("4947314") EPO; ("6008800")).PN. ("6188484") or and video Search Text bas\$3 or JPO; 2004/02/20 DERWEN 14:34 USPAT; US-PGP Τ; JPO; EPO; UB; EPO; DERWEN 14:10 Τ, В IBM\_TD DERWEN 14:36 UB; IBM\_ID IBM\_TD US-PGP USPAT; US-PGP USPAT; DBs 2004/02/20 2004/02/20 Time Stamp Comments Error Definition Err ors 0 0 0

ω 7 σ BRS BRS BRS Type L10 L8 L9 ۲ # w 9 w Hits sensing near3 device\$1) captur\$3 or sensor\$@ or image-pickup or image near3 JPO; imag\$3 near3 devic\$2 or 9 and (camera\$1 or "CCD" artwork\$3 or art adj1 or lineart or line adj1 inscrib\$4 or penmanship\$4 print\$4) or scrib\$4 or handprint\$4 or cursiv\$4 handwrit\$4 or writ\$4 or pencil adj1 like\$1 or pencil\$3 or pencillike\$1 7 and (pen\$1 or penlike\$1 or USPAT; sensing near3 device\$1) captur\$3 or sensor\$@ or image-pickup or image near3 JPO; imag\$3 near3 devic\$2 or 7 and (camera\$1 or "CCD" hand adjl (writ\$4 or (drawing\$1 or work\$3) (drawing\$! or art) or Search Text or or US-PGP or UB; or UB; JPO; EPO; EPO; EPO; DERWEN 14:39 DERWEN 14:38 UB; DERWEN 14:36 IBM\_TD IBM\_TD US-PGP USPAT; US-PGP USPAT; IBM\_TD DBs 2004/02/20 2004/02/20 2004/02/20 Time Stamp Comments Error Definition Err 0 gro 0 0

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tec\$4 near3 4) near7(surface or JPO; rate or paper or board DERWE yer) same robot\$3 T; (robot\$3 near3 arm) (writ\$3 or draw\$3 or JPO; 3) (robot\$3 near5(writ\$3 JPO; aw\$3 or mark\$3))  US-PG US-PG US-PG US-PG US-PG IBM_T B IBM_T B IBM_T B IBM_T IBM_T B IBM_T IBM_T IBM_T IBM_T IBM_T									ſ
tec\$4 near3 4) near7 (surface or ate or paper or board DERWEN 13:1 yer) same robot\$3 T; (robot\$3 near3 arm) (writ\$3 or draw\$3 or DERWEN 12:5 3)  IBM_TD B US-PGP UB; TGPO; DERWEN 12:5 1BM_TD B IBM_TD IBM_TD IBM_TD IBM_TD			20 12	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	near5( writ\$; mark\$3))	ហ	L6	BRS	ω
US-PGP UB; EPO; JPO; DERWEN 13:11 3 T; IBM_TD B			2004	TU EU GP;	near3 arm) or draw\$3	2	Ľ5	BRS	N
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US-PGP UB; EPO; DERWEN T; USPAT; USPAT; USPAT; USPAT; USPAT; USPAT; USPAT; TPO; DERWEN T; TBM_TD B IBM_TD B IBM_TD B IBM_TD B	DBs USPAT;
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y	BRS	Ľ12	<b>.</b>	( detec\$4 near3 (move\$4 or USPAT; position))near3(surface or US-PGF substrate or wafer or paper UB; or board or layer or partical or media or chip partical or media or chip or sub-strate)and((robot\$3 DERWEN near3 (arm or hand))near3(writ\$4 or B		2004, 15:30	02/19	02/19	02/19

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(( detec\$4 or recogniz\$4 or determin\$5) near5 (move\$4 or position))near5(surface or substrate or wafer or paper or board or layer or partical or media or chip or sub-strate)same((robot\$3 near3 (arm or hand))near3 (writ\$4 or draw\$4))	(( detec\$4 or recogniz\$4 or determin\$5) near3 US-PGP (move\$4 or position)) near5(surface or UB; substrate or wafer or paper EPO; or board or layer or partical or media or chip partical or media or chip or sub-strate) same((robot\$3 T; near3 (arm or hand)) near3(writ\$4 or B	( detec\$4 near3 (move\$4 or position))near5(surface or substrate or wafer or paper or board or layer or partical or media or chip or sub-strate)and((robot\$3 near3 (arm or hand))near3 (writ\$4 or draw\$4))	Search Text
USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	USPAT; US-PGP UB; EPO; JPO; DERWEN 1 IBM_TD B	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	DBs
2004/02/19 15:34	2004/02/19 15:33	2004/02/19 15:31	Time Stamp
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or sub-strate)and((robot\$3 or board or layer or substrate or wafer or paper EPO; or board or layer or (( detec\$4 or recogniz\$4 or determin\$5) near5 draw\$4)) hand))near3(writ\$4 or near3 (arm or position))near5(surface or (move\$4 or Search Text DERWEN 15:34 UB; Ш IBM\_TD US-PGP USPAT; DBs Time Stamp Comments Error Definition Err ors 0

3 BRS L3	2 BRS L2	1 BRS L1	, J. C.
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(( vision near3( bas\$3 or system))or robot\$3) same(( writ\$3 or draw\$3 or mark\$3) near7 (implement or tool or instrument or article or device))	(vision-based or vision near3 bas\$3) same(writ\$3 near7 (implement or tool or instrument or article or device))	(vision-based or vision near3 bas\$3) same(writ\$3 near3 (implement or tool or instrument or article or device))	
USPAT; US-PGP US-PGP (( EPO; 2004/ \$3) JPO; 2004/ Or DERWEN 16:03	USPAT; US-PGP UB; EPO; Or JPO; DERWEN T; IBM_TD B	USPAT; US-PGP UB; EPO; Or JPO; DERWEN T; IBM_TD B	!
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O			2004/02/16 14:20	USPAT; US-PGP UB; EPO; JPO; JPO; DERWEN 14:2 T; IBM_TD B	4 and (video near3 frame\$1)same ( target or object or reference near3 object)	U	Ľ <sub>5</sub>	BRS	σ
O			2004/02/16 14:52	USPAT; US-PGP UB; EPO; JPO; DERWEN 14:5 T; IBM_TD B	3 and (CCD or "CCD" or image-pikup\$4 or image near3 pickup or imag\$3 or camera\$1 or detec\$4 near3 device\$1)	4 3 5	L4	BRS	44
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robot\$3 same(( writ\$3 or draw\$3 or mark\$3) near7 (implement or tool or instrument or article or device))	7 and (video near3 frame\$1)same ( target or object or reference near3 object)	4 and robot\$3	Search Text
USPAT; US-PGP UB; EPO; JPO; DERWEN 15:54 T; IBM_TD B	USPAT; US-PGP UB; EPO; 2004, JPO; 2004, DERWEN 17:2' T; IBM_TD B	US-PAT; US-PGP UB; EPO; 2004, JPO; DERWEN 14:20 T; IBM_TD B	DBS
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10 and ( target or object or reference near3 object)	10 and (video near3 frame\$1)near5 ( target or object or reference near3 object)	USPAT  9 and (writ\$3 or draw\$3 or EPO; mark\$3) near7 (surface or JPO; substrate or paper or board DERWE or layer)  IBM_T	Search Text
USPAT; US-PGP UB; EPO; 2004, JPO; DERWEN 15:5, T; IBM_TD B	USPAT; US-PGP UB; EPO; 2004, JPO; 14:45 DERWEN 14:45 T; IBM_TD B	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	DBs
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13	BRS	L13	60	12 and (detec\$4 or search\$4 or find\$3 or recogniz\$3)same(target or object or reference near3 object or mark)	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	2004/02/16			0
14	BRS	L14	5 3	13 and (CCD or "CCD" or image-pikup\$4 or image near3 pickup or imag\$3 or camera\$1 or detec\$4 near3 device\$1)	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	2004/02/16			0
15	IS&R	L15	41	(("6249591") or ("6044165")).PN.	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	2004/02/16			0

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16	BRS	L16	4777	382/103,106,151,152,153,186,313,314,315,188,189,187;34,8/169,113,116,170,171,175;3,56/3;235/411.ccls.	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD	2004/02/16 15:54			0
17	BRS	L17	V	16 and robot\$3 same(( writ\$3 or draw\$3 or mark\$3)  near7 (implement or tool or instrument or article or device))	USPAT; US-PGP UB; k\$3) EPO; 2004/0; 1 or JPO; 17:25 r T; IBM_TD B	2004/02/16			0
18	BRS	L18	7	17 and (target or object or reference near3 object or reference near3 point or fiducial near3 mark)	USPAT; US-PGP UB; EPO; JPO; JPO; 15: T; IBM_TD B	2004/02/16 15:55			0

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USPAT; US-PGP UB; EPO; JPO; DERWEN 16:12 T; IBM_TD B	USPAT; US-PGP UB; EPO; 2004 JPO; 16:1 DERWEN 16:1 IBM_TD B	USPAT; US-PGP UB; EPO; JPO; DERWEN T; IBM_TD B	DBs
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24 BRS L24 290 writ	22 sa recog searc	robot\$3 22 BRS L22 761 (impleme instrume device))	Type L # Hits
(robot\$3 near3 arm) near5( writ\$3 or draw\$3 or mark\$3)	me(detect\$4 or niz\$3 or find\$3 or h\$3)near5(substrate o or board or surface)	<pre>same(( writ\$3 or r mark\$3) near5 int or tool or int or article or</pre>	Search Text
USPAT; US-PGP UB; EPO; 2004, JPO; 17:48 T; DERWEN 17:48 IBM_TD	USPAT; US-PGP UB; EPO; 2004/ JPO; 2004/ T; DERWEN 17:48 T; IBM_TD	USPAT; US-PGP UB; EPO; JPO; DERWEN 17:4 T; IBM_TD B	DBs
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